

# SYSTEM FOR RESISTING LIMB MOVEMENT

**Publication number:** US5201772 (A)

**Publication date:** 1993-04-13

**Inventor(s):** MAXWELL SCOTT M [US] +

**Applicant(s):** MAXWELL SCOTT M [US] +

**Classification:**

**- international:** A61F5/01; A61H1/02; B25J9/16; B25J13/08; B25J19/00;  
A61F5/01; A61H1/02; B25J9/16; B25J13/08; B25J19/00;  
(IPC1-7): A61F2/48; G09B19/00

**- European:** A61F5/01D; B25J9/16K; B25J13/08V; B25J19/00B

**Application number:** US19910648733 19910131

**Priority number(s):** US19910648733 19910131

**Also published as:**

WO9213504 (A1)  
JP6505407 (T)  
ES2074877 (T3)  
EP0569489 (A1)  
EP0569489 (B1)

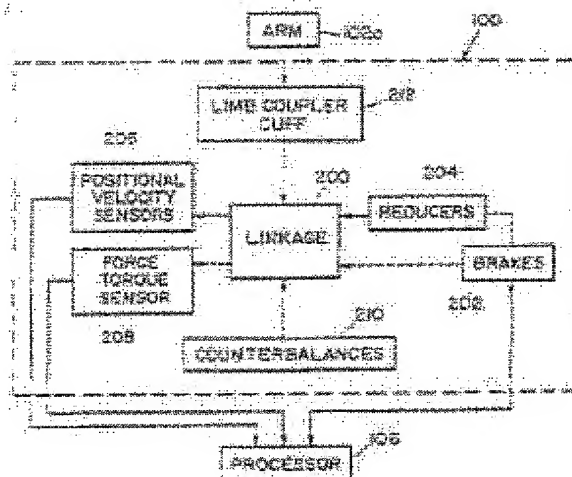
more >>

**Cited documents:**

US4078670 (A)  
US4237873 (A)  
US4760850 (A)  
US5020790 (A)  
EP0380060 (A2)

## Abstract of US 5201772 (A)

A six degree of freedom limb movement resistance system is described in which a linkage system of links and joints couples a fixed point in space to a movable end-point of the linkage. A limb coupling cuff is attached to the end point. Variable resistance force can be applied to the linkage via computer controls through a feedback path from position and velocity sensors. The linkage endpoint force acting to resist limb motion is in a direction opposite to the endpoint velocity vector.



Data supplied from the **espacenet** database — Worldwide